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EXAMINER

DHARIA, PRABODH M

ART UNIT PAPER NUMBER

2673

DATE MAILED: 11/28/2005

Please find below and/or attached an Office communication concerning this application or proceeding.

Office Action Summary	Application No. 09/909,857	Applicant(s) HILDRETH ET AL.	
	Examiner Prabodh M. Dharja	Art Unit 2673	

-- The MAILING DATE of this communication appears on the cover sheet with the correspondence address --

Period for Reply

A SHORTENED STATUTORY PERIOD FOR REPLY IS SET TO EXPIRE 3 MONTH(S) OR THIRTY (30) DAYS, WHICHEVER IS LONGER, FROM THE MAILING DATE OF THIS COMMUNICATION.

- Extensions of time may be available under the provisions of 37 CFR 1.136(a). In no event, however, may a reply be timely filed after SIX (6) MONTHS from the mailing date of this communication.
- If NO period for reply is specified above, the maximum statutory period will apply and will expire SIX (6) MONTHS from the mailing date of this communication.
- Failure to reply within the set or extended period for reply will, by statute, cause the application to become ABANDONED (35 U.S.C. § 133). Any reply received by the Office later than three months after the mailing date of this communication, even if timely filed, may reduce any earned patent term adjustment. See 37 CFR 1.704(b).

Status

- 1) ☒ Responsive to communication(s) filed on 04 October 2005.
- 2a) ☐ This action is **FINAL**. 2b) ☒ This action is non-final.
- 3) ☐ Since this application is in condition for allowance except for formal matters, prosecution as to the merits is closed in accordance with the practice under *Ex parte Quayle*, 1935 C.D. 11, 453 O.G. 213.

Disposition of Claims

- 4) ☒ Claim(s) 3-8 and 11-101 is/are pending in the application.
- 4a) Of the above claim(s) 1,2,9 and 10 is/are withdrawn from consideration.
- 5) ☐ Claim(s) _____ is/are allowed.
- 6) ☒ Claim(s) 3-8, 11-91 and 96-101 is/are rejected.
- 7) ☒ Claim(s) 92-95 is/are objected to.
- 8) ☐ Claim(s) _____ are subject to restriction and/or election requirement.

Application Papers

- 9) ☐ The specification is objected to by the Examiner.
- 10) ☒ The drawing(s) filed on 02 November 2001 is/are: a) ☒ accepted or b) ☐ objected to by the Examiner.
Applicant may not request that any objection to the drawing(s) be held in abeyance. See 37 CFR 1.85(a).
Replacement drawing sheet(s) including the correction is required if the drawing(s) is objected to. See 37 CFR 1.121(d).
- 11) ☐ The oath or declaration is objected to by the Examiner. Note the attached Office Action or form PTO-152.

Priority under 35 U.S.C. § 119

- 12) ☐ Acknowledgment is made of a claim for foreign priority under 35 U.S.C. § 119(a)-(d) or (f).
- a) ☐ All b) ☐ Some * c) ☐ None of:
1. ☐ Certified copies of the priority documents have been received.
 2. ☐ Certified copies of the priority documents have been received in Application No. _____.
 3. ☐ Copies of the certified copies of the priority documents have been received in this National Stage application from the International Bureau (PCT Rule 17.2(a)).

* See the attached detailed Office action for a list of the certified copies not received.

Attachment(s)

- | | |
|---|---|
| 1) <input checked="" type="checkbox"/> Notice of References Cited (PTO-892) | 4) <input type="checkbox"/> Interview Summary (PTO-413)
Paper No(s)/Mail Date. _____ |
| 2) <input type="checkbox"/> Notice of Draftsperson's Patent Drawing Review (PTO-948) | 5) <input type="checkbox"/> Notice of Informal Patent Application (PTO-152) |
| 3) <input checked="" type="checkbox"/> Information Disclosure Statement(s) (PTO-1449 or PTO/SB/08)
Paper No(s)/Mail Date <u>02-12-02, 01-30-03</u> | 6) <input type="checkbox"/> Other: _____ |

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1. **Status:** Receipt is acknowledged of papers submitted on 10-04-2005 under amendments and new claims have been placed of record in the file. Claims 3-8,11-101 are pending in this action. Claims 1,2,9,10 are cancelled.

Claim Rejections - 35 USC § 102

2. The following is a quotation of the appropriate paragraphs of 35 U.S.C. 102 that form the basis for the rejections under this section made in this Office action:

A person shall be entitled to a patent unless –

(e) the invention was described in (1) an application for patent, published under section 122(b), by another filed in the United States before the invention by the applicant for patent or (2) a patent granted on an application for patent by another filed in the United States before the invention by the applicant for patent, except that an international application filed under the treaty defined in section 351(a) shall have the effects for purposes of this subsection of an application filed in the United States only if the international application designated the United States and was published under Article 21(2) of such treaty in the English language.

3. Claims 99,100 are rejected under 35 U.S.C. 102(e) as being anticipated by Gordon et al. (6,661,918 B1).

Regarding Claim 99, Gordon et al. teaches a method of using computer vision (Col. 1, Lines 10-13, Col. 4, lines 30-40) to interface with a computer (Col. 4, lines 15-22, Lines 43-45), the method comprising: generating a scene description that includes an indication of a three-dimensional position of a feature included in a scene (Col. 3, Line 64 to Col. 4, Line 17); analyzing the scene description including the indication of the three-dimensional position of the feature to determine position information of an object within the scene (Col. 3, Line 51 to Col. 4, Line 17); and using the position information to control a computer application (Col. 3, Line 51 to Col. 4, Line 60).

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Regarding Claim 100, Gordon et al. teaches generating the scene description comprises generating the scene description from stereo images (Col. 3, Line 64 to Col. 4, Line 2)

4. Claims 3-8,11,12, 23,54-70,101 are rejected under 35 U.S.C. 103(a) as being unpatentable over Gordon et al. (6,661,918 B1) as applied to claims 99,100 above, and further in view of Pryor et al. (US 2004/0046736 A1) .

Regarding Claim 3, Gordon et al. teaches wherein: generating a scene description comprises generating a scene description that includes an indication of a three-dimensional position of a feature included in a scene (Col. 3, Line 64 to Col. 4, Line 17); and an indication a shape of the feature; and analyzing the scene description comprises analyzing the scene description including the indication of the three-dimensional position of the feature and the indication of the shape of the feature to determine position information of an object (Col. 3, Line 51 to Col. 4, Line 60).

However, Gordon et al. fails to specifically recognizing a gesture associated with the object by analyzing changes in the position information of the object, and controlling the computer application based on the recognized gesture.

However, Pryor et al. teaches recognizing a gesture associated with the object by analyzing changes in the position information of the object, and controlling the computer application based on the recognized gesture (page 10, paragraph 239-241).

Thus it would have been obvious to one in the ordinary skill in the art at the time of invention was made to incorporate the teaching of Pryor et al. in Gordon et al. teaching, to be

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able to provide computer and a technique for determining the position of the object with help of definition of shape of object.

Regarding Claim 4, Pryor et al. teaches determining an application state of the computer application; and using the application state in recognizing the gesture (Page 10, paragraph 239-241).

Regarding Claim 5, Pryor et al. teaches the object is the user (page 10, paragraph 243, 244).

Regarding Claim 6, Pryor et al. teaches the object is a part of the user (page 10, paragraph 243,244).

Regarding Claim 7, Pryor et al. teaches providing feedback to the user relative to the computer application (page 10, paragraph 238-244)

Regarding Claim 8, Pryor et al. teaches processing the stereo image to determine position information of the object further includes mapping the position information from position coordinates associated with the object to screen coordinates associated with the computer application (page 10, paragraphs 238-244).

Regarding Claim 11, Pryor et al. teaches processing the stereo image further includes: analyzing the scene description to identify a change in position of the object; and mapping the

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change in position of the object (*page 9, paragraph 224)

Regarding Claim 12, Pryor et al. teaches processing the stereo image to produce the scene description further includes: processing the stereo image to identify matching pairs of features in the stereo image; and calculating a disparity and a position for each matching feature pair to create a scene description (page 9, paragraph 224).

Regarding Claim 23, Pryor et al. teaches for each feature pair in the scene description, calculating real world coordinates by transforming the disparity and position of each feature pair relative to the real world coordinates of the stereo image (page 10, paragraph 238-241).

Regarding Claim 54, Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121); processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of

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the object (page 8, paragraph 170-173); the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); select a control object appearing within the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249).

Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Regarding Claim 55, Pryor et al. teaches the process selects as a control object a detected object appearing closest to the video cameras and within the object detection region (page 11, paragraphs 247-249).

Regarding Claim 56, Pryor et al. teaches the control object is a human hand (page 11, paragraph 256).

Regarding Claim 57, Pryor et al. teaches a horizontal position of the control object relative to the video cameras is mapped to an x-axis screen coordinate of the position indicator

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(page 10, paragraph 238).

Regarding Claim 58, Pryor et al. teaches a vertical position of the control object relative to the video cameras is mapped to a y-axis screen coordinate of the position indicator (page 10, paragraph 238).

Regarding Claim 59, Pryor et al. teaches the processor is configured to: map a horizontal position of the control object relative to the video cameras to a x-axis screen coordinate of the position indicator; map a vertical position of the control object relative to the video cameras to a y-axis screen coordinate of the position indicator; and emulate a mouse function using the combined x-axis and y-axis screen coordinates provided to the application program (page 10, paragraphs 238-242).

Regarding Claim 60, Pryor et al. teaches the processor is further configured to emulate buttons of a mouse using gestures derived from the motion of the object position (page 10, paragraphs 241-244)

Regarding Claim 61, Pryor et al. teaches the processor is further configured to emulate buttons of a mouse based upon a sustained position of the control object in any position within the object detection region for a predetermined time period (page 10, paragraphs 241-244).

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Regarding Claim 62, Pryor et al. teaches the processor is further configured to emulate buttons of a mouse based upon a position of the position indicator being sustained within the bounds of an interactive display region for a predetermined time period (page 10, paragraphs 241-244).

Regarding Claim 63, Pryor et al. teaches the processor is further configured to map a z-axis depth position of the control object relative to the video cameras to a virtual z-axis screen coordinate of the position indicator (page 27, paragraph 529).

Regarding Claim 64, Pryor et al. teaches the processor is further configured to: map a x-axis position of the control object relative to the video cameras to an x-axis screen coordinate of the position indicator; map a y-axis position of the control object relative to the video cameras to a y-axis screen coordinate of the position indicator; and map a z-axis depth position of the control object relative to the video cameras to a virtual z-axis screen coordinate of the position indicator (page 10, paragraphs 229-242, page 13, paragraph 297)

Regarding Claim 65, Pryor et al. teaches a position of the position indicator being within the bounds of an interactive display region triggers an action within the application program (page 12, paragraphs 262-272).

Regarding Claim 66, Pryor et al. teaches movement of the control object along a z-axis depth position that covers a predetermined distance within a predetermined time period triggers a

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selection action within the application program (page 10, paragraphs 229-242, page 13, paragraph 297).

Regarding Claim 67, Pryor et al. teaches a position of the control object being sustained in any position within the object detection region for a predetermined time period triggers a selection action within the application program (page 12, paragraphs 262-272, page 10, paragraphs 229-242, page 13, paragraph 297).

Regarding Claim 68, Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121), the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173); select a control object appearing within

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the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249) and define sub regions within the object detection region; identify a sub region occupied by the control object; associate with that sub region an action that is activated when the control object occupies that sub region; and apply the action to interface with a computer application (page 12, paragraphs 273-276, page 13, paragraphs 291-294, page 10, paragraphs 230 –239, sub-regions rotated or targeted to blend together or access to alter original target in sub-region with to generate 3D image).

Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Regarding Claim 69, Pryor et al. teaches the action associated with the sub region is further defined to be an emulation of the activation of keys associated with a computer keyboard (page 12, paragraphs 273-276).

Regarding Claim 70, Pryor et al. teaches a position of the control object being sustained in any sub region for a predetermined time period triggers the action (page 12, paragraphs 262-276, page 10, paragraphs 229-242, page 13, paragraph 297).

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Regarding Claim 101, Gordon et al. teaches wherein: generating a scene description comprises generating a scene description that includes an indication of a three-dimensional position of a feature included in a scene (Col. 3, Line 64 to Col. 4, Line 17); and an indication a shape of the feature; and analyzing the scene description comprises analyzing the scene description including the indication of the three-dimensional position of the feature and the indication of the shape of the feature to determine position information of an object (Col. 3, Line 51 to Col. 4, Line 60).

Pryor et al. shape the indication of the shape of the feature to determine position information of an object (pages 6,7, paragraphs 121-136).

Claim Rejections - 35 USC § 103

5. The following is a quotation of 35 U.S.C. 103(a) which forms the basis for all obviousness rejections set forth in this Office action:

(a) A patent may not be obtained though the invention is not identically disclosed or described as set forth in section 102 of this title, if the differences between the subject matter sought to be patented and the prior art are such that the subject matter as a whole would have been obvious at the time the invention was made to a person having ordinary skill in the art to which said subject matter pertains. Patentability shall not be negated by the manner in which the invention was made.

6. Claims 13-22,24-53 are rejected under 35 U.S.C. 103(a) as being unpatentable over Gordon et al. (6,661,918 B1) in view of Pryor et al. (US 2004/0046736 A1) and Onda (6,125,198).

Regarding Claim 13, Gordon et al. teaches wherein: generating a scene description comprises generating a scene description that includes an indication of a three-dimensional

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position of a feature included in a scene (Col. 3, Line 64 to Col. 4, Line 17); and an indication a shape of the feature; and analyzing the scene description comprises analyzing the scene description including the indication of the three-dimensional position of the feature and the indication of the shape of the feature to determine position information of an object (Col. 3, Line 51 to Col. 4, Line 60).

However, Gordon et al. fails to specifically recite or disclose shape the indication of the shape of the feature to determine position information of an object.

However, Pryor et al. shape the indication of the shape of the feature to determine position information of an object (pages 6,7, paragraphs 121-136); capturing the stereo image further includes capturing a reference image from a reference camera and a comparison image from a comparison camera; and processing the stereo image further includes processing the reference image and the comparison image to create pairs of features (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135, 136, 148-160, page 10, paragraph 238,239); processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the feature information (page 8, paragraphs 170-173) and analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173).

Thus it would have been obvious to one in the ordinary skill in the art at the time of invention was made to incorporate the teaching of Pryor et al. in Gordon et al. teaching, to be able to provide computer and a technique for determining the position of the object with help of definition of shape of object.

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Gordon et al. teaches wherein: generating a scene description comprises generating a scene description that includes an indication of a three-dimensional position of a feature included in a scene (Col. 3, Line 64 to Col. 4, Line 17); and an indication a shape of the feature; and analyzing the scene description comprises analyzing the scene description including the indication of the three-dimensional position of the feature and the indication of the shape of the feature to determine position information of an object (Col. 3, Line 51 to Col. 4, Line 60).

However, Gordon et al. fails to specifically recite capturing a reference image from a camera.

However, Onda teaches capturing a reference image from a camera (Col. 11, Lines 9-25, Lines 43-67).

Thus it would have been obvious to one in the ordinary skill in the art at the time of invention was made to incorporate the teaching of Onda in Gordon et al. teaching, to be able to provide computer and a technique for matching stereo images and a method of detecting disparity between these images to detect positional information in the image pickup space based on stereo images, volume compression of overall stereo images display control of these stereo images and for the optical flow extraction of moving images.

Regarding Claim 14, Onda teaches processing the stereo image to identify matching pairs of features in the stereo image further includes: identifying features in the reference image; generating for each feature in the reference image a set of candidate matching features in the comparison image; and producing a feature pair by selecting a best matching feature from the set of candidate matching features for each feature in the reference image (Col. 11, Lines 9-25,

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Lines 43-58).

Regarding Claim 15, Pryor et al. teaches processing the stereo image further includes filtering the reference image and the comparison image (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135, 136, 148-160, page 10, paragraph 238,239).

Gordon et al. teaches processing the stereo image further includes filtering the reference image and the comparison image (Col. 5, Line 43, to Col. 6, Line 3).

Regarding Claim 16, Pryor et al. teaches the feature pair further includes: calculating a match score and rank for each of the candidate matching features; and selecting the candidate matching feature with the highest match score to produce the feature pair (page 13, paragraph 293-295).

Regarding Claim 17, Pryor et al. teaches generating for each feature in the reference image, a set of candidate matching features further includes; selecting candidate matching features from a predefined range in the comparison image (page 31, paragraph 293-295)

Regarding Claim 18, Pryor et al. teaches feature pairs are eliminated based upon the match score of the candidate matching feature (page 13, paragraph 293-295).

Regarding Claim 19, Pryor et al. teaches feature pairs are eliminated if the match score of the top ranking candidate matching feature is below a predefined threshold (page 7, paragraph 135-160, page 10, paragraph 238,239, page 13, paragraph 293-295).

Regarding Claim 20, Pryor et al. teaches the feature pair is eliminated if the match score of the top ranking candidate matching feature is within a predefined threshold of the match score of a lower ranking candidate matching feature (page 7, paragraph 135-160, page 10, paragraph 238,239, page 13, paragraph 293-295).

Regarding Claim 21, Pryor et al. teaches calculating the match score further includes: identifying those feature pairs that are neighboring; adjusting the match score of feature pairs in proportion to the match score of neighboring candidate matching features at similar disparity; and selecting the candidate matching feature with the highest adjusted match score to create the feature pair (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135-160, page 10, paragraph 238,239, page 13, paragraph 293-295).

Onda teaches calculating the match score further includes: identifying those feature pairs that are neighboring; adjusting the match score of feature pairs in proportion to the match score of neighboring candidate matching features at similar disparity; and selecting the candidate matching feature with the highest adjusted match score to create the feature pair (Col. 11, Lines 9-25, Lines 43-58, Col. 14, Lines 29-59, Col. 15, Lines 13-39).

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Regarding Claim 22, Pryor et al. teaches feature pairs are eliminated by: applying the comparison image as the reference image and the reference image as the comparison image to produce a second set of feature pairs; and eliminating those feature pairs in the original set of feature pairs which do not have a corresponding feature pair in the second set of feature pairs (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135-160, page 10, paragraph 238,239).

Regarding Claim 24, Pryor et al. teaches selecting features further includes dividing the reference image and the comparison image of the stereo image into blocks (page 21, paragraph 451 to page 22, paragraph 451-454).

Regarding Claim 25, Pryor et al. teaches the feature is described by a pattern of luminance of the pixels contained with the blocks (page 8, paragraph 173-176, page 21, paragraph 451 to page 22, paragraph 451-454).

Regarding Claim 26, Pryor et al. teaches dividing further includes dividing the images into pixel blocks having a fixed size (page 8, paragraph 173-176, page 21, paragraph 451 to page 22, paragraph 451-454).

Regarding Claim 27, Onda teaches the pixel blocks are 8.times.8 pixel blocks (Col. 13, Line 60 to Col. 14, Line 28).

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Regarding Claim 28, Onda teaches analyzing the scene description to determine the position information of the object further includes cropping the scene description to exclude feature information lying outside of a region of interest in a field of view (Col. 11, Lines 9-25, Lines 43-58).

Regarding Claim 29, Pryor et al. teaches cropping further includes establishing a boundary of the region of interest (page 13, paragraph 293,294).

Regarding Claim 30, Gordon et al. teaches analyzing the scene description to determine the position information of the object further includes: clustering the feature information in a region of interest into clusters having a collection of features by comparison to neighboring feature information within a predefined range; and calculating a position for each of the clusters (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6).

Onda teaches analyzing the scene description to determine the position information of the object further includes: clustering the feature information in a region of interest into clusters having a collection of features by comparison to neighboring feature information within a predefined range; and calculating a position for each of the clusters (Col. 11, Lines 9-25, Lines 43-58, Col. 13, Line 60 to Col. 14, Line 59).

Regarding Claim 31, Grdon et al. teaches eliminating those clusters having less than a predefined threshold of features (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6).

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Onda teaches eliminating those clusters having less than a predefined threshold of features (page 10, paragraph 234, Lines 1-4, paragraph 238).

Regarding Claim 32, Pryor et al. teaches selecting the position of the clusters that match a predefined criteria; recording the position of the clusters that match the predefined criteria as object position coordinates; and outputting the object position coordinates (page 10, paragraph 234, Lines 1-4, paragraph 238).

Gordon et al. teaches selecting the position of the clusters that match a predefined criteria; recording the position of the clusters that match the predefined criteria as object position coordinates; and outputting the object position coordinates (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6).

Regarding Claim 33, Gordon et al. teaches determining the presence of a user from the clusters by checking features within a presence detection region (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6).

Regarding Claim 34, Gordon et al. teaches calculating the position for each of the clusters excludes those features in the clusters that are outside of an object detection region (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6).

Regarding Claim 35, Onda teaches defining a dynamic object detection region based on the object position coordinates (Col. 1, Lines 12-19).

Regarding Claim 36, Pryor et al. teaches the dynamic object detection region is defined relative to a user's body (page 10, paragraph 244).

Regarding Claim 37, Pryor et al. teaches defining a body position detection region based on the object position coordinates (page 30, paragraph 583).

Regarding Claim 38, Pryor et al. teaches the body position detection region further includes detecting a head position of the user (page 14, paragraph 308).

Regarding Claim 39, Pryor et al. teaches smoothing the motion of the object position coordinates to eliminate jitter between consecutive image frames (page 3, paragraphs 53,54).

Regarding Claim 40, Pryor et al. teaches calculating hand orientation information from the object position coordinates (page 5, paragraph 99, page 10, paragraphs 231-234 and 238-241).

Regarding Claim 41, Pryor et al. teaches outputting the object position coordinates further includes outputting the hand orientation information (page 5, paragraph 99, page 10,

paragraphs 231-234 and 238-241).

Regarding Claim 42, page 3, paragraph 53,54 teaches smoothing the changes in the hand orientation information (page 3, paragraphs 53,54).

Regarding Claim 43, Pryor et al. teaches defining the dynamic object detection region includes: identifying a position of a torso-divisioning plane from the collection of features; and determining the position of a hand detection region relative to the torso-divisioning plane in the axis perpendicular to the torso divisioning plane (page 3, paragraphs 53,54, page 5, paragraphs 99, 105-115, page 6, paragraph 116, page 9, paragraphs 216-224, page 10, paragraphs 230-234 and 238-241).

Regarding Claim 44, Pryor et al. teaches identifying a body center position and a body boundary position from the collection of features; identifying a position indicating part of an arm of the user from the collection of features using the intersection of the feature pair cluster with the torso divisioning plane; and identifying the arm as either a left arm or a right arm using the arm position relative to the body position (page 3, paragraphs 53,54, page 5, paragraphs 99, 105-115, page 6, paragraph 116, page 9, paragraphs 216-224, page 10, paragraphs 230-234 and 238-241).

Regarding Claim 45, Pryor et al. teaches establishing a shoulder position from the body center position, the body boundary position, the torso-divisioning plane, and the left arm or the

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right arm identification (page 3, paragraphs 53,54, page 5, paragraphs 99, 105-115, page 6, paragraph 116, page 9, paragraphs 216-224, page 10, paragraphs 230-234 and 238-241).

Regarding Claim 46, Pryor et al. teaches the dynamic object detection region includes determining position data for the hand detection region relative to the shoulder position (page 3, paragraphs 53,54, page 5, paragraph 99, page 10, paragraphs 231-234 and 238-241).

Regarding Claim 47, Pryor et al. teaches smoothing the position data for the hand detection region (page 3, paragraphs 53,54, page 5, paragraph 99, page 10, paragraphs 231-234 and 238-241).

Regarding Claim 48, Pryor et al. teaches determining the position of the dynamic object detection region relative to the torso divisioning plane in the axis perpendicular to the torso divisioning plane; determining the position of the dynamic object detection region in the horizontal axis relative to the shoulder position; and determining the position of the dynamic object detection region in the vertical axis relative to an overall height of the user using the body boundary position (page 3, paragraphs 53,54, page 5, paragraphs 99, 105-115, page 6, paragraph 116, page 9, paragraphs 216-224, page 10, paragraphs 230-234 and 238-241).

Regarding Claim 49, Pryor et al. teaches the dynamic object detection region includes: establishing the position of a top of the user's head using topmost feature pairs of the collection of features unless the topmost feature pairs are at the boundary; and determining the position of a

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hand detection region relative to the top of the user's head (page 3, paragraphs 53,54, page 5, paragraphs 99, 105-115, page 6, paragraph 116, page 9, paragraphs 216-224, page 10, paragraphs 230-234 and 238-241).

Regarding Claim 50, Pryor et al. teaches a method of using stereo vision to interface with a computer (page 1, paragraph 3), the method comprising: capturing a stereo image using a stereo camera (page 8, paragraph 173); processing the stereo image to determine position information of an object in the stereo image (page 10, paragraph 239), the object being controlled by a user (page 10, paragraph 239); processing the stereo image to identify feature information, to produce a scene description from the feature information (page 11, paragraph 247), and to identify matching pairs of features in the stereo image (page 5, paragraphs 114,115); calculating a disparity and a position for each matching feature pair to create the scene description (page 13, paragraphs 293-297, page 4, paragraph 79); analyzing the scene description in a scene analysis process to determine position information of the object; clustering the feature information in a region of interest into clusters having a collection of features by comparison to neighboring feature information within a predefined range (page 5, paragraphs 111-115, page 6, paragraphs 116-124)); calculating a position for each of the clusters; and using the position information allow the user to interact with a computer application (page 10, paragraphs 238-244).

Gordon et al. teaches eliminating those clusters having less than a predefined threshold of features (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6); selecting the position of the clusters that match a predefined criteria; recording the position of the clusters that

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match the predefined criteria as object position coordinates; and outputting the object position coordinates (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6); determining the presence of a user from the clusters by checking features within a presence detection region (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6) and calculating the position for each of the clusters excludes those features in the clusters that are outside of an object detection region (Col. 5, Line 43 to Col. 6, line 3, Col. 11, Line 29 to Col. 12, Line 6) and Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Onda teaches the pixel blocks are 8.times.8 pixel blocks (Col. 13, Line 60 to Col. 14, Line 28); analyzing the scene description to determine the position information of the object further includes cropping the scene description to exclude feature information lying outside of a region of interest in a field of view (Col. 11, Lines 9-25, Lines 43-58); analyzing the scene description to determine the position information of the object further includes: clustering the feature information in a region of interest into clusters having a collection of features by comparison to neighboring feature information within a predefined range; and calculating a position for each of the clusters (Col. 11, Lines 9-25, Lines 43-58, Col. 13, Line 60 to Col. 14, Line 59); eliminating those clusters having less than a predefined threshold of features (page 10,

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paragraph 234, Lines 1-4, paragraph 238) and defining a dynamic object detection region based on the object position coordinates (Col. 1, Lines 12-19).

Regarding Claim 51, Pryor et al. teaches mapping the position of the object from the feature information from camera coordinates to screen coordinates associated with the computer application; and using the mapped position to interface with the computer application (page 11, paragraph 247-249).

Regarding Claim 52, Pryor et al. teaches recognizing a gesture associated with the object by analyzing changes in the position information of the object in the scene description; and combining the position information and the gesture to interface with the computer application (page 11, paragraph 247-249).

Regarding Claim 53, Pryor et al. teaches the step of capturing the stereo image further includes capturing the stereo image using a stereo camera (page 5, paragraph 111-115).

7. Claims 71-91,96-98 are rejected under 35 U.S.C. 103(a) as being unpatentable over Pryor et al. (US 2004/0046736 A1) in view of Gordon et al. (6,661,918 B1) and Maurer et al. (US 2001/0033675 A1).

Regarding Claim 71, Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121), processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173); the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); select a control object appearing within the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249) and identify an object perceived as the largest object appearing in the intersecting field of view of the cameras (page 10, paragraphs 243,244) and positioned at a predetermined depth range (page 13, paragraphs 297, page 18, paragraph 383); select the object as an object of interest; determine a position coordinate representing a position of the object of interest; and use the position coordinate as an object control point to control the application program (page 18, paragraphs 382, 385, 386,387).

However, Prior et al. fails to specifically recite a reference camera.

However, Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).a reference camera and capturing a reference image from a camera (Col. 4, Lines 21-60).

Thus it would have been obvious to one in the ordinary skill in the art at the time of invention was made to incorporate the teaching of Gordon et al. in Pryor et al. teaching, to be able to provide computer and a technique for automatically distinguishing between a background scene and foreground objects in an image.

Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121), processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster

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of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173); the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); select a control object appearing within the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249) and identify an object perceived as the largest object appearing in the intersecting field of view of the cameras (page 10, paragraphs 243,244) and positioned at a predetermined depth range (page 13, paragraphs 297, page 18, paragraph 383); select the object as an object of interest; determine a position coordinate representing a position of the object of interest; and use the position coordinate as an object control point to control the application program (page 18, paragraphs 382, 385, 386,387).

However, Prior et al. fails to specifically teach the indicator is an avatar

However, Maurer et al. teaches the indicator is an avatar (page 5, paragraph 56, (page 6, paragraphs 66-69, page 7, paragraphs 71-73).

Thus it would have been obvious to one in the ordinary skill in the art at the time of invention was made to incorporate the teaching of Maurer et al. in Pryor et al. teaching, to be able to provide a dynamic facial feature sensing, and more particularly, to a vision-based motion capture system that allows real-time finding, tracking and classification of facial features for input into a graphics engine that animates an avatar.

Regarding Claim 72, Pryor et al. teaches the process causes the processor to: determine and store a neutral control point position; map a coordinate of the object control point relative to the neutral control point position; and use the mapped object control point coordinate to control the application program (page 11, paragraphs 246-249).

Regarding Claim 73, Pryor et al. teaches the process causes the processor to: define a region having a position based upon the position of the neutral control point position; map the object control point relative to its position within the region; and use the mapped object control point coordinate to control the application program (page 11, paragraphs 246-255).

Regarding Claim 74, Pryor et al. teaches the process causes the processor to: transform the mapped object control point to a velocity function; determine a viewpoint associated with a virtual environment of the application program; and use the velocity function to move the viewpoint within the virtual environment (page 13, paragraph 297, page 14, paragraph 298-310).

Regarding Claim 75, Pryor et al. teaches the process causes the processor to map a coordinate of the object control point to control a position of an indicator within the application program (page 13, paragraph 297, page 14, paragraph 298-310, page 11, paragraphs 246-255).

Regarding Claim 76, Pryor et al. teaches capturing the stereo image further includes capturing a reference image from a reference camera and a comparison image from a comparison camera; and processing the stereo image further includes processing the reference image and the

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comparison image to create pairs of features (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135, 136, 148-160, page 10, paragraph 238,239).

Maurer et al. teaches the indicator is an avatar (page 5, paragraph 56, (page 6, paragraphs 66-69, page 7, paragraphs 71-73).

Regarding Claim 77, Maurer et al. teaches the process causes the processor to map a coordinate of the object control point to control an appearance of an indicator within the application program (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 78, Maurer et al. teaches the indicator is an avatar (page 6, paragraphs 66-69, page 7, paragraphs 71-73)

Regarding Claim 79, Maurer et al. teaches the object of interest is a human appearing within the intersecting field of view (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 80, Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to

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produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121), processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173); the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); select a control object appearing within the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249) and identify an object perceived as the largest object appearing in the intersecting field of view of the cameras (page 10, paragraphs 243,244) and positioned at a predetermined depth range (page 13, paragraphs 297, page 18, paragraph 383); select the object as an object of interest; determine a position coordinate representing a position of the object of interest; and use the position coordinate as an object control point to control the application program (page 18, paragraphs 382, 385, 386,387) and the control region being positioned at a predetermined location (page 18, paragraph 387) and having a predetermined size relative to a size and a location of the object of interest; search the control region for a point associated with the object of interest that is closest to the cameras (page 18, paragraph 387, Lines 1-6) and within the control region; select the point associated with the object of interest as a control point if the point associated with the object of interest is within the control region (page

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18, paragraph 387, 6-12); and map position coordinates of the control point, as the control point moves within the control region, to a position indicator associated with the application program (page 18, paragraph 387, Lines 1-12, paragraph 391).

Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Maurer et al. teaches the object of interest is a human appearing within the intersecting field of view (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 81, Pryor et al. teaches the processor is operable to: map a horizontal position of the control point relative to the video cameras to an x-axis screen coordinate of the position indicator; map a vertical position of the control point relative to the video cameras to a y-axis screen coordinate of the position indicator; and emulate a mouse function using a combination of the x-axis and the y-axis screen coordinates (page 10, paragraphs 229-242, page 13, paragraph 297).

Regarding Claim 82, Pryor et al. teaches the processor is operable to: map a x-axis position of the control point relative to the video cameras to an x-axis screen coordinate of the position indicator; map a y-axis position of the control point relative to the video cameras to a y-

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axis screen coordinate of the position indicator; and map a z-axis depth position of the control point relative to the video cameras to a virtual z-axis screen coordinate of the position indicator (page 13, paragraph 297, page 14, paragraph 298-310, page 11, paragraphs 246-255).

Regarding Claim 83, Pryor et al. teaches capturing the stereo image further includes capturing a reference image from a reference camera and a comparison image from a comparison camera; and processing the stereo image further includes processing the reference image and the comparison image to create pairs of features (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135, 136, 148-160, page 10, paragraph 238,239).

Maurer et al. teaches the object of interest is a human appearing within the intersecting field of view (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 84, Prior et al. teaches the control point is associated with a human hand appearing within the control region (page 10, paragraphs 230-238).

Regarding Claim 85, Pryor et al. teaches a stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) for interfacing with an application program running on a computer (page 1, paragraph 3, Lines 5-7, page 5, paragraph 111, Line 2) the stereo vision system (page 1, paragraph 3, Lines 5-7, paragraph 28, 11-13) comprising: first and second video cameras (page 5, paragraph 111, Lines 2,3) arranged in an adjacent configuration and operable to produce a series of stereo video images (page 6, paragraph 119, Lines 1-7, figure 1c); and a

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processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (page 6, paragraphs 119-121), the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras (page 11, paragraphs 247, 249); processing the stereo image further includes processing the stereo image to identify feature information and produce a scene description from the cluster of features information (page 8, paragraphs 170-173); analyzing the scene description in a scene analysis process to determine position information of the object (page 8, paragraph 170-173); select a control object appearing within the object detection region; and map position coordinates of the control object to a position indicator associated with the application program as the control object moves within the object detection region (page 11, paragraphs 247-249) and identify an object perceived as the largest object appearing in the intersecting field of view of the cameras (page 10, paragraphs 243,244) and positioned at a predetermined depth range (page 13, paragraphs 297, page 18, paragraph 383); select the object as an object of interest; determine a position coordinate representing a position of the object of interest; and use the position coordinate as an object control point to control the application program (page 18, paragraphs 382, 385, 386,387) and as the hand objects move within the object detection region, to positions of virtual hands associated with an avatar rendered by the application program (page 11, paragraphs 251-257, hand motion generates virtual mouse operation or as appointing device or paint brush).

Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature

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information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Gordon et al. teaches a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras (Col. 4, Lines 41-60); processing the stereo image further includes processing the stereo image to identify feature information (Col. 3, Line 64 to Col. 4, Line 4) and produce a scene description from the cluster of features information (Col. 4, Line 49 to Col. 5, Line 59); analyzing the scene description in a scene analysis process to determine position information of the object (Col. 9, Lines 7-43).

Maurer et al. teaches the avatar takes the form of a human-like body (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 86, Prior et al. teaches the process selects the up to two hand objects from the objects appearing in the intersecting field of view that are closest to the video cameras and within the object detection region (page 10, paragraphs 230-238).

Regarding Claim 87, Pryor et al. teaches capturing the stereo image further includes capturing a reference image from a reference camera and a comparison image from a comparison camera; and processing the stereo image further includes processing the reference image and the comparison image to create pairs of features (page 6, paragraph 117, Lines 1-4, paragraph 119, paragraph 121, 128, page 7, paragraph 134, Lines 3-5, paragraph 135, 136, 148-160, page 10, paragraph 238, 239).

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Maurer et al. teaches the avatar takes the form of a human-like body (page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

Regarding Claim 88, Maurer et al. teaches the avatar is rendered in and interacts with a virtual environment forming part of the application program (page 1, paragraph 2).

Regarding Claim 89, Maurer et al. teaches the processor further executes a process to compare the positions of the virtual hands associated with the avatar to positions of virtual objects within the virtual environment to enable a user to interact with the virtual objects within the virtual environment (page 1, paragraph 2).

Prior et al. teaches the processor further executes a process to compare the positions of the virtual hands associated with positions of virtual objects within the virtual environment to enable a user to interact with the virtual objects within the virtual environment (page 10, paragraphs 230-243).

Regarding Claim 90, Prior et al. teaches the processor further executes a process to: detect position coordinates of a user within the intersecting field of view (page 10, paragraphs 230-243); and Maurer et al. teaches map the position coordinates of the user to a virtual torso of the avatar rendered by the application program (page 1, paragraph 2, page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83).

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Regarding Claim 91, Prior et al. the process moves at least one of the virtual hands to a neutral position if a corresponding hand object is not selected (page 12, paragraphs 263-270).

Maurer et al. teaches the avatar is rendered in and interacts with a virtual environment forming part of the application program (page 1, paragraph 2).

Regarding Claim 96, Maurer et al. teaches a virtual knee position associated with the avatar is derived by the application program and used to refine an appearance of the avatar (page 1, paragraph 2, page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83, since it can work with face and facial features it can work with elbow or knee).

Regarding Claim 97, Maurer et al. teaches a virtual elbow position associated with the avatar is derived by the application program and used to refine an appearance of the avatar (page 1, paragraph 2, page 6, paragraphs 66-69, page 7, paragraphs 71-73, 80-83, since it can work with face and facial features it can work with elbow or knee).

Regarding Claim 98, Pryor et al. teaches a third video camera arranged in an adjacent configuration with the first and second video cameras and operable to produce the series of stereo video images (page 1, paragraph 3, Lines 4-7).

Allowable Subject Matter

8. Claims 92-95 objected to as being dependent upon a rejected base claim, but would be allowable if rewritten in independent form including all of the limitations of the base claim and any intervening claims.

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9. The following is an examiner's statement of reasons for allowance:

a stereo vision system for interfacing with an application program running on a computer, the stereo vision system comprising: first and second video cameras arranged in an adjacent configuration and operable to produce a series of stereo video images; and a processor operable to receive the series of stereo video images and detect objects appearing in an intersecting field of view of the cameras, the processor executing a process to: define an object detection region in three-dimensional coordinates relative to a position of the first and second video cameras; select up to two hand objects from the objects appearing in the intersecting field of view that are within the object detection region; and map position coordinates of the hand objects, as the hand objects move within the object detection region, to positions of virtual hands associated with an avatar rendered by the application program and the processor further executes a process to: detect position coordinates of a user within the intersecting field of view; and map the position coordinates of the user to a velocity function that is applied to the avatar to enable the avatar to roam through a virtual environment rendered by the application program and the velocity function includes a neutral position denoting zero velocity of the avatar; map the position coordinates of the user relative to the neutral position into torso coordinates associated with the avatar so that the avatar appears to lean and compare the position of the virtual hands associated with the avatar to positions of virtual objects within the virtual environment to enable the user to interact with the virtual objects while roaming through the virtual environment.

The cited references of 892's fail to anticipate individually or render obviousness individually as well as in combination the underlined above.

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Any comments considered necessary by applicant must be submitted no later than the payment of the issue fee and, to avoid processing delays, should preferably accompany the issue fee. Such submissions should be clearly labeled "Comments on Statement of Reasons for Allowance."

Response to Arguments

10. Applicant's arguments with respect to claim 50, 54, 68, 71, 80, 85, 99 have been considered but are moot in view of the new ground(s) of rejection.

Conclusion

11. The prior art made of record and not relied upon is considered pertinent to applicant's disclosure.

Baker et al. (20040135886 A1) Moving imager camera for track and range capture.

12. Any inquiry concerning this communication or earlier communications from the examiner should be directed to Prabodh M Dharia whose telephone number is 571-272-7668.

The examiner can normally be reached on M-F 8AM to 5PM.

13. If attempts to reach the examiner by telephone are unsuccessful, the examiner's supervisor, Bipin Shalwala can be reached on 571-272-7681. The fax phone number for the organization where this application or proceeding is assigned is 571-273-8300.

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14. Information regarding the status of an application may be obtained from the Patent Application Information Retrieval (PAIR) system. Status information for published applications may be obtained from either Private PAIR or Public PAIR. Status information for unpublished applications is available through Private PAIR only. For more information about the PAIR system, see <http://pair-direct.uspto.gov>. Should you have questions on access to the Private PAIR system, contact the Electronic Business Center (EBC) at 866-217-9197 (toll-free).

Any response to this action should be mailed to:

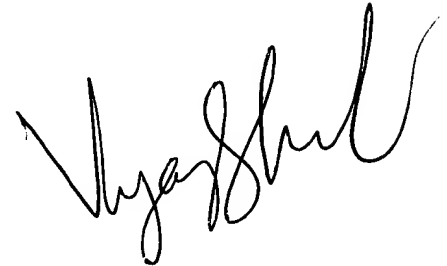
Commissioner of Patents and Trademarks

Washington, D.C. 20231

PD

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November 18, 2005

A handwritten signature in black ink, appearing to read 'Vijay Shankar', is written over a light gray grid background.

VIJAY SHANKAR
PRIMARY EXAMINER